

IN THE CLAIMS

1. (Previously Presented) A method of rehabilitation using an actuator type that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume, comprising:

exercising a patient at a first place of rehabilitation selected from a bed, a wheel-chair, a clinic and a home, using an actuator of said actuator type which interacts with a motion of said patient; and

second exercising said patient at a second place of rehabilitation selected from a bed, a wheel-chair, a clinic and a home using a second actuator of said actuator type which interacts with a motion of said patient;

wherein said first exercising and said second exercising utilize a same movement mechanism design for moving the actuators.

2. (Previously Presented) A method according to claim 1, wherein said first and said second exercising are performed using a same rehabilitation apparatus.

3. (Previously Presented) A method according to claim 1, wherein said motion mechanism is motorized.

4. (Previously Presented) A method according to claim 3, wherein said motion and said force are controlled by a controller.

5. (Currently Amended) A method according to claim 3, wherein said motion mechanism is capable of applying a force of at least 10 Kg to a tip of said actuator.

6. (Previously Presented) A method according to claim 3, wherein said motion mechanism is capable of applying a force of different magnitudes in different directions of motion said actuator.

7. (Previously Presented) A method according to claim 1, wherein said motion mechanism is adapted to apply selective resistance to motion of said actuator.

8. (Currently Amended) A method according to claim 1, wherein said actuator is adapted to interact with said motion in a plurality of modes including at least causing said motion, guiding said motion and recording said motion.

9. (Previously Presented) A method according to claim 8, wherein said first and said second exercising use different motion interaction modes.

10. (Previously Presented) A method according to claim 1, wherein at least one of said first and said second exercising are performed in water.

11. (Previously Presented) A method according to claim 1, wherein said first and said second exercising are performed on a same limb.

12. (Previously Presented) A method according to claim 1, wherein said first and said second exercising are different exercises.

13. (Previously Presented) A method according to claim 1, comprising keeping track of progress of said patient including said first and said second exercising, in a same controller coupled with said second actuator.

14. (Previously Presented) A method according to claim 1, wherein said actuator is rigid.

15. (Previously Presented) A method of rehabilitation using an actuator that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume, comprising:

- exercising a first organ type of a patient using said actuator; and
- exercising a second organ type of the patient using said actuator;

16. (Previously Presented) A method according to claim 15, comprising replacing an attachment to said patient of said rehabilitation device between said exercising.

17. (Previously Presented) A method according to claim 15, the actuator comprises a controller which controls said interaction.

18. (Previously Presented) A method according to claim 17, wherein said controller is programmed with a plurality of different exercises for different limbs.

19. (Previously Presented) A method according to claim 15, comprising adjusting at least one of a spatial position and orientation of said actuator relative to said patient, between said exercises.

20. (Previously Presented) A rehabilitation kit, comprising:

an actuator that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter; in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume;

a tip on said actuator; and

a plurality of attachments modularly exchangeable for said tip, at least two of which are adapted to fit different organs.

21. (Previously Presented) A kit according to claim 20, wherein at least one of said attachments is powered via said actuator.

22. (Previously Presented) A kit according to claim 20, wherein at least one of said attachments is capable of rotation in three axes of rotations.

23. (Previously Presented) A device for rehabilitation, comprising:

a motorized actuator adapted to support a movement by a person by at least one of resisting motion, guiding motion and causing motion; and

a controller configured to control said actuator,

wherein, said controller is programmed to provide rehabilitation exercising for patient's switchable between a plurality of modes in which one or more of motivation, cognitive ability and motor ability is either high or low.

24. (Previously Presented) A device according to claim 23, wherein said controller is configured to provide instructions in a selectable one of at least three information presentation modes and complexity levels.

25. (Previously Presented) A device according to claim 23, wherein said controller is configured to provide support for motor activity of said patient in a selectable one of at least three levels of assistance.

26. (Previously Presented) A device according to claim 23, wherein said controller is configured to provide incentive feedback to said patient in a selectable one of at least three levels of incentive.

27. (Previously Presented) A method of rehabilitation using an actuator that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume, comprising:

coupling said actuator to a person in a home setting; and
performing a daily activity by said person, wherein said actuator interacts with said activity to enhance rehabilitation.

28. (Previously Presented) A method according to claim 27, wherein said daily activity is outdoors.

29. (Previously Presented) A method according to claim 27, wherein said actuator interacts using a stored rehabilitation plan.

30. (Previously Presented) A method according to claim 27, wherein said actuator reports to a remote location on a progress of rehabilitation.

31. (Previously Presented) A method according to claim 27, wherein said actuator prevents unsafe motions by said patient.

32. (Previously Presented) A method according to claim 27, comprising first practicing said daily activity at a rehabilitation clinic.

33. (Previously Presented) A method of rehabilitation, comprising:

rehabilitating a first patient on a first rehabilitation device;

rehabilitating a second patient on a second rehabilitation device; and

passing information regarding rehabilitation between said two devices, said information including at least one of a score, current progress, spatial position of a portion of the patient and a game play.

34. (Previously Presented) A method according to claim 33, wherein said patients play a game together using said devices for input and output.

35. (Previously Presented) A method according to claim 34, wherein said patients play against each other.

36. (Currently Amended) A method according to claim 34, wherein said first rehabilitation device provides a different support ~~for~~ for said first patient than said second device supplies for said second patient, to compensate for differences in ability between the two patients.

37. (Previously Presented) A method according to claim 33, wherein said information is passed in real-time.

38. (Previously Presented) A method according to claim 33, wherein said information is passed using a wireless connection.

39. (Previously Presented) A method according to claim 33, comprising monitoring said first and said second patients by a remote therapist.

40. (Previously Presented) A method according to claim 33, comprising remotely connecting into a therapy group by said patients.

41. (Previously Presented) A method according to claim 33, wherein said two devices are in a same room.

42. (Previously Presented) A rehabilitation system configuration, comprising:
- A first rehabilitation device; and
 - A second rehabilitation device linked by a wireless data link with said first rehabilitation device such that the two rehabilitation devices can act in synchrony.
43. (Previously Presented) A method of cooperative rehabilitation, comprising:
- providing a first actuator that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume;
 - providing a second actuator that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume;
 - engaging said first and said second actuators by a patient and by a non-therapist, respectively; and
 - rehabilitating said patient using said first actuator and said non-therapist.
44. (Previously Presented) A method according to claim 43, wherein said non-therapist is a blood relative.
45. (Previously Presented) A method according to claim 43, comprising guiding said non-therapist and said patient by instructions by a controller.
46. (Previously Presented) A method according to claim 43, wherein said non-therapist is under an age of 18.
47. (Previously Presented) A method according to claim 43, wherein said non-therapist is under an age of 10.
48. (Previously Presented) A method according to claim 43, wherein said providing is at a home of said non-therapist.

49. (Previously Presented) A method according to claim 43, wherein said non-therapist has fewer than 50 hours experience in physical therapy.

50. (Previously Presented) A method according to claim 43, wherein said non-therapist has fewer than 10 hours experience in physical therapy.

51. (New) A rehabilitation system configuration using an actuator type that includes a movement mechanism capable of applying a force that interacts with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least three degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume, comprising:

a first rehabilitation device at a first place of rehabilitation using a first actuator of said actuator type and a first operational setting; and,

a second rehabilitation device at a second place of rehabilitation using a second actuator of said actuator type and a second operational setting.

52. (New) A system according to claim 51, wherein the first and second places of rehabilitation are selected from a bed, a wheel-chair, a clinic, a hospital and a home.

53. (New) A system according to claim 51, wherein the first operational setting includes applying a force that interacts with a motion of a patient's limb in at least three degrees of freedom and the second operational setting includes applying a force that interacts with a motion of a patient's limb in two degrees of freedom.

54. (New) A system according to claim 51, wherein the first operational setting includes having a software set and the second operational setting includes having only a portion of the software set.

55. (New) A system according to claim 51, wherein the first operational setting includes having a software set and the second operational setting includes having a different software set.

56. (New) A system according to claim 51, wherein the first operational setting includes a set of modes and the second operation setting includes having only a portion of the set of modes.

57. (New) A system according to claim 51, wherein the first rehabilitation device is provided with a first display type and the second rehabilitation device is provided with a different display type.

58. (New) A system according to claim 51, wherein the second rehabilitation device is adapted for the second place of rehabilitation.

59. (New) A system according to claim 58, wherein the second rehabilitation device is adapted by providing mobility.

60. (New) A system according to claim 58, wherein second first rehabilitation device is adapted by changing its size relative to the first rehabilitation device.

61. (New) A system according to claim 51, wherein the first and second rehabilitation devices are connected in a network.

62. (New) A system according to claim 61, wherein the network is provided with a database shared between at least the first and second rehabilitation devices.

63. (New) A system according to claim 61, wherein the system is adapted to generate a report on the patient from the first and second rehabilitation devices.

64. (New) A system according to claim 51, wherein the first rehabilitation device and the second rehabilitation device are monitored by the same therapist.

65. (New) A system according to claim 51, wherein the first and second rehabilitation devices are adapted to be used by the same patient.

66. (New) A rehabilitation system configuration, comprising:

a first rehabilitation device at a first place of rehabilitation using an actuator that includes a movement mechanism capable of applying a force adapted to interact with a motion of a patient's limb in a volume of at least 30 cm in diameter, in at least two degrees of freedom of motion of the actuator and capable of preventing substantial motion in any point in any direction in said volume; and,

a second rehabilitation device at a second place of rehabilitation that includes a movement mechanism operable by the patient's limb in a volume of at least 30 cm in diameter, in at least two degrees of freedom and capable of preventing substantial motion in any point in any direction in said volume;

67. (New) A rehabilitation system according to claim 66, further comprising a controller adapted to control the actuator of the first rehabilitation device in accordance with a program.